Google scholar   correcting (gait OR walk OR posture) by chang [Search]   Advanced Scholar Search
                                                                            Scholar Preferences

Scholar All articles Recent articles   Results **1 - 10** of about **5,000**. (0.54 sec)

[PDF] ▶ Subacromial impingement syndrome: the effect of **changing posture** on shoulder
range of ...
JS Lewis, C Wright, A Green - J Orthop Sports Phys Ther, 2005 - azpt.com
... assess **posture** and devise rehabilitation programs to **correct posture**, there is little ...
pathology is associated with a high morbidity **rate**, with ... **Changing Posture** ...
Cited by 27 - Related articles - View as HTML - All 4 versions

Design and control of a pendulum driven hopping robot- ▶ kfupm.edu.sa [PDF]
F Iida, C Aul - Proc of the IEEE/RSJ International Conference on ..., 2002 - eprints.kfupm.edu.sa
... structure, the robot was able to **correct** its **posture** ... were then developed for straight
walk- ing, reversing ... est is the investigation of different **gait** patterns. ...
Cited by 15 - Related articles - View as HTML - All 8 versions

[PDF] ▶ Understanding Orbits
A Motion, M Weight, I Momentum, C Momentum ... - faa.gov
... at 1 m/s (about the speed of a brisk **walk**), we must ... p Δt ----- **change** in **momentum**
change in time ... Thus, his model of gravity had been **correct** all along! ...
Related articles - View as HTML

Gait generating device of legged mobile robot and legged mobile robot controller
T Takenaka, T Matsumoto, T Yoshiike... - US Patent App. 10/561,988, 2004 - Google Patents
... BODY POSITION/ VELOCITY, INITIAL BODY **POSTURE** ANGLE/**ANGULAR** ... DETERMINE **GAIT**
PARAMETERS
OF CURRENT TIME **GAIT**. S026 S028 SUBROUTINE FOR **CORRECTING** CURRENT TIME ...
All 6 versions

Controller of legged mobile robot
T Takenaka, T Matsumoto, T Yoshiike... - US Patent App. 10/562,327, 2004 - Google Patents
... **range**, then the motion of a desired **gait** is determined by **correcting** the provisional ...
60 90 80->, JOYSTICK f ISTCALCUIATION UNIT **POSTURE** SENSOR [A/D ...
Cited by 2 - Related articles - All 8 versions

Human hamstring muscles adapt to eccentric exercise by **changing** optimum length.-
▶ psu.edu [PDF]
CL BROCKETT, DL MORGAN, UWE Proske - Medicine & Science in Sports & Exercise, 2001 - acsm-msse.org
... If our hypothesis is **correct**, such a measure would ... position while maintaining a rigid
body **posture** to restrict ... After the exercise, there was a **change** in the ...
Cited by 111 - Related articles - BL Direct - All 7 versions

[PDF] ▶ ... plane characterization of normal human ankle function across a **range** of walking
gait ...
ML Palmer - 2002 - Citeseer
... normal ankle function could also provide direction in **correcting** ... instructed to **walk**
at that same self-selected speed ... flat to the time when the **gait** cycle begins ...
Cited by 32 - Related articles - View as HTML - All 8 versions

Energy-saving mechanisms in walking and running- ▶ biologists.org [PDF]

Google scholar (gait OR walking OR walk OR run OR running [Search] Advanced Scholar Search
Scholar Preferences

Scholar All articles Recent articles   Results **1 - 10** of about **12,300**. (0.14 sec)

Adjusting step length for rough terrain locomotion
JK Hodgins, MN Raibert - IEEE Transactions on Robotics and Automation, 1991 - ieeexplore.ieee.org
... to specify direction and speed of travel for **walking** on smooth ... This machine was able
to **walk** up and down ... travels around a circle with a **running gait** that uses ...
Cited by 138 - Related articles - All 3 versions

A **running** experiment of **humanoid** biped- ▶ history.com [PDF]
T Nagasaki, S Kajita, K Kaneko, K Yokoi, K ... - 2004 IEEE/RSJ International Conference on ... -
ieeexplore.ieee.org
... Most of them focus on biped **walk**- ing as an ... of '18 [kg] weight and could **run** at 1.25 ...
prevent ordinary **humanoid** activities such as **walking**, carrying objects ...
Cited by 21 - Related articles - All 5 versions

[PDF] ▶ **Running** in the real world: **adjusting** leg stiffness for different surfaces
DP Ferris, M Louie, CT Farley - Proceedings: Biological Sciences, 1998 - pubmedcentral.nih.gov
... to adjust leg stijjness allows humans to **run** similarly on ... PR 1979 The in£uence of
track compliance on **running**. ... at dijjerent speeds of human **walking** and **running** ...
Cited by 94 - Related articles - View as HTML - BL Direct - All 16 versions

Sky-hook suspension control of a quadruped **walking** vehicle
K Yoneda, H Iiyama, S Hirose - 1994 IEEE International Conference on Robotics and ..., 1994 -
ieeexplore.ieee.org
... A chart of foot forces indicates the **gait** includes 2-leg ... body were slightly larger
than that of statically stable **walking**, TITAN VI could **walk** stably enough ...
Cited by 40 - Related articles - BL Direct

Adaptive **gait** control of a biped **robot** based on realtime sensing of the ground profile
S Kajita, K Tani - Autonomous Robots, 1997 - Springer
... our biped **robot**, Meltran II, to **walk** over ground ... This paper discusses the adaptive
gait control method of a ... the descriptions in this paper to **walking** on ground ...
Cited by 78 - Related articles - BL Direct - All 4 versions

Evidence for spring loaded inverted pendulum **running** in a hexapod **robot**- ▶ dtic.mil [PDF]
R Altendorfer, U Saranli, H Komsuoglu, D ... - Experimental robotics VII, 2001 - books.google.com
... plate while the **robot** performs an alternating tripod **gait**. ... established in [16] to
distinguish **walking** from **running**. ... time as the data trajectory is **run** with the ...
Cited by 14 - Related articles - BL Direct - All 23 versions

[PDF] ▶ Cheap" rapid locomotion of a quadruped **robot**: Self-stabilization of bounding **gait**
F Iida, R Pfeifer - Intelligent Autonomous Systems, 2004 - people.csail.mit.edu
... a relatively complicated behavior of dynamic **walking** if it ... On the other hand, for
the **run**- ning/hopping ... versa, which results in the stable **gait** over multiple ...
Cited by 22 - Related articles - View as HTML - All 2 versions

Planning strategies for the ambler **walking robot**
D Wettergreen, H Thomas, C Thorpe - IEEE International Conference on Systems Engineering ..., 1990 -
ieeexplore.ieee.org

Google scholar (correction OR correcting OR adjustment OR a [Search] Advanced Scholar Search
Scholar Preferences

Scholar All articles Recent articles Results **1 - 10** of about **60,800**. (0.37 sec)

The development of Honda **humanoid robot**- ▶ snu.ac.kr [PDF]
K Hirai, M Hirose, Y Haikawa, T Takenaka - 1998 IEEE International Conference on Robotics and ..., 1998 -
ieeexplore.ieee.org
... the C-ATGRF to an appropriate position by **adjusting** each foot's ... In the previous example,
the **Model** ZMP control ... the robot from maintaining the **desired** posture. ...
Cited by 986 - Related articles - BL Direct - All 5 versions

... dynamic **walking** of a quadruped **robot** on irregular terrain by using neural system **model**
H Kimura, Y Fukuoka, Y Hada, K Takase - IEEE/RSJ. Intelligent Robots and Systems, 2000 - Springer
... central pattern generator) and reflexes receiving **adjustment** signals from ... 2. Neural
oscillator as a **model** of a CPG ... Adaptive Dynamic **Walking** of a Quadruped **Robot** ...
Cited by 81 - Related articles - BL Direct - All 4 versions

Planning **walking** patterns for a biped **robot**- ▶ cmu.edu [PDF]
Q Huang, K Yokoi, S Kajita, K Kaneko, H Arai, ... - IEEE Transactions on robotics and automation, 2001 -
ieeexplore.ieee.org
... motion without first designing the **desired** ZMP trajectory ... Hodgins and MH Raibert,
"**Adjusting** step length ... A theoretically motivated reduced order **model** for the ...
Cited by 288 - Related articles - BL Direct - All 16 versions

Making feasible **walking** motion of **humanoid** robots from human motioncapture data
A Dasgupta, Y Nakamura - 1999 IEEE International Conference on Robotics and ..., 1999 - ieeexplore.ieee.org
... suggested the use of iipper body inotioii **correction** for stabilizing a ... groniicl coii-
tact point, obtained froin the foot **model** of Sec ... t,aken as the **desired** ZMP ...
Cited by 101 - Related articles - BL Direct - All 2 versions

Adaptive dynamic **walking** of a quadruped **robot** on irregular terrain based on biological ...
Y Fukuoka, H Kimura, AH Cohen - The International Journal of Robotics Research, - ijr.sagepub.com
... The neural system **model** consists of a central pattern ... The **desired** angle and P-gain
of each joint in ... Takase Adaptive **Running** of a Quadruped **Robot** Using Forced ...
Cited by 209 - Related articles - BL Direct - All 2 versions

Posture control of a cockroach-like **robot**
GM Nelson, RD Quinn - 1998 IEEE International Conference on Robotics and ..., 1998 - ieeexplore.ieee.org
... ne represents a **desired** vertical load responsibility for each ... animals may "dwell"
around this **model** even on rough terrain by **adjusting** body orientation. ...
Cited by 82 - Related articles - BL Direct - All 7 versions

[PDF] ▶ Stable control of a simulated one-legged **running robot** with hip and leg compliance
M Ahmadi, M Buehler - IEEE Transactions on Robotics and Automation, 1997 - Citeseer
... For this **model**, proper spring selection and initial conditions ... It also tracks changes
in **desired robot** velocity and ... energy savings based on a **robot** design with ...
Cited by 100 - Related articles - View as HTML - BL Direct - All 5 versions

Dynamic **walking** control of a biped **robot** along a potential energyconserving orbit
S Kajita, T Yamaura, A Kobayashi - IEEE Transactions on Robotics and Automation, 1992 - ieeexplore.ieee.org
... His **robot** could generate the **gait** pattern passively without ... of the trajectories of

an ideal biped **model**. **...** realize the biped locomotion of **desired** velocity and ...
Cited by 174 - Related articles - All 4 versions

Adjusting step length for rough terrain locomotion
JK Hodgins, MN Raibert - IEEE Transactions on Robotics and Automation, 1991 - ieeexplore.ieee.org
... planning a path, selecting a foothold, and **adjusting** step length. ... cue occurred late
in the step, the **adjustment** was made ... trace for the body and a **model** of the ...
Cited by 138 - Related articles - All 3 versions

A robust layered control system for a mobile **robot**- ▶ siu.edu [PDF]
R Brooks - IEEE journal of robotics and automation, 1986 - ieeexplore.ieee.org
... The **robot** must **model** ... each piece must be built in order to **run** the **robot** at all ... solution,
we slice the problem on the basis of **desired** external manifestations of ...
Cited by 6107 - Related articles - All 78 versions
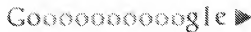
Gooooooooogle ▶

Result Page: 1 2 3 4 5 6 7 8 9 10   **Next**

(correction OR correcting OR adjust Search

Go to Google Home - About Google - About Google Scholar

©2009 Google

Web Images Videos Maps News Shopping Gmail more ▾   Sign in

Google scholar (correction OR correcting OR adjustment OR ✸ [Search]   Advanced Scholar Search
                                                                            Scholar Preferences

Scholar All articles Recent articles   Results 1 - 10 of about **2,450**. (0.12 sec)

A three-dimensional passive-dynamic **walking robot** with two legs and knees
SH Collins, M Wisse, A Ruina - The International Journal of Robotics Research, 2001 - ijr.sagepub.com
... which tends to constantly control actuation to **force** a system ... we would use trial,
error, and **correction** to minimize ... of **angular momentum** about a **vertical** axis. ...
Cited by 270 - Related articles - BL Direct

A hop towards **running humanoid** biped- ▶ tistory.com [PDF]
S Kajita, T Nagasaki, K Kaneko, K Yokoi, K .. - 2004 IEEE International Conference on Robotics and ... -
ieeexplore.ieee.org
... by-product of this **adjustment**, we obtained smaller touchdown impact ... steady hopping
motion more clearly from the **vertical** floor reaction **force** shown in Fig ...
Cited by 44 - Related articles - BL Direct - All 7 versions

Adjusting step length for rough terrain locomotion
JK Hodgins, MN Raibert - IEEE Transactions on Robotics and Automation, 1991 - ieeexplore.ieee.org
... occurred late in the step, the **adjustment** was made ... roll information was provided
by a **vertical** gyroscope ... develop the control algorithms for **adjusting** step length ...
Cited by 138 - Related articles - All 3 versions

[PDF] ▶ Stable control of a simulated one-legged **running robot** with hip and leg compliance
M Ahmadi, M Buehler - IEEE Transactions on Robotics and Automation, 1997 - Citeseer
... to remain closely synchronized with the **vertical** motion to ... spring is massless and
the spring **force** is axial ... All the **robot** variables and parameters are denied in ...
Cited by 100 - Related articles - View as HTML - BL Direct - All 5 versions

SCOUT: A simple quadruped that walks, climbs, and runs- ▶ martinbuehler.net [PDF]
M Buehler, R Battaglia, A Cocosco, G Hawker, ... - 1998 IEEE International Conference on Robotics and ...,
1998 - ieeexplore.ieee.org
... the rear legs, giving the body enough **vertical** velocity for ... the 7th and final phase,
a **torque** is applied ... forward speed during flight (via **adjusting** the impact ...
Cited by 98 - Related articles - BL Direct - All 7 versions

A **running** experiment of **humanoid** biped- ▶ tistory.com [PDF]
T Nagasaki, S Kajita, K Kaneko, K Yokoi, K ... - 2004 IEEE/RSJ International Conference on . . -
ieeexplore.ieee.org
... The **vertical momentum** is calculated considering the compliant elements ... equipped with
a 6-axes **force** sensor and ... the total(linear and **angular**) **momentum** for the ...
Cited by 21 - Related articles - All 5 versions

... and construction of a series of compact **humanoid** robots and development of biped **walk**
...
T Furuta, T Tawara, Y Okumura, M Shimizu, ... - Robotics and Autonomous Systems, 2001 - Elsevier
... strategy has provisions for real-time **gait adjustment** due to ... initial speed and the
kicking **force** F k ... of inverted pendulum measured from the **vertical** line, q m ...
Cited by 69 - Related articles - BL Direct - All 2 versions

A new control method for **walking** robots based on **angular momentum**

K Mitobe, G Capi, Y Nasu - Mechatronics, 2004 - Elsevier
... To simplify our experiments, the **vertical** height of the ankle ... By using the **force** sensor data, it is easy ... the body balance is maintained by **adjusting** the point ...
Cited by 19 - Related articles - All 3 versions

Stabilization of lateral motion in passive dynamic **walking**
AD Kuo - The International Journal of Robotics Research, 1999 - ijr.sagepub.com
... measured counterclockwise with respect to the **vertical** so that ... i − 1 from (4). Finally, the **angular momentum** of the ... termed long- or short-period **gait** cycles. ...
Cited by 152 - Related articles - BL Direct - All 2 versions

Simulating leaping, tumbling, landing and balancing humans- ▶ gatech.edu [PDF]
WL Wooten, JK Hodgins, PA Studios, CA ... - IEEE International Conference on Robotics and ..., 2000 - ieeexplore.ieee.org
... tum- bling controller modifies **angular** velocity by **adjusting** the tightness ... slower than that of the **vertical** leap with ... Table 3: A **correction** term for the foot ...
Cited by 64 - Related articles - BL Direct - All 12 versions

Goooooooooogle ▶

Result Page: 1 2 3 4 5 6 7 8 9 10   **Next**

(correction OR correcting OR adjust | Search |

Go to Google Home - About Google - About Google Scholar

©2009 Google

IEEE *Xplore*
DIGITAL LIBRARY

Welcome United States Patent and Trademark Office

Search Session History   BROWSE   SEARCH   IEEE XPLORE GUIDE

Wed, 30 Sep 2009, 11:55:28 AM EST

Search Query Display

Edit an existing query or
compose a new query in the
Search Query Display.

**Select a search number (#)
to:**

- Add a query to the Search
  Query Display
- Combine search queries
  using AND, OR, or NOT
- Delete a search
- Run a search

Recent Search Queries

#	Query
#1	(((mobile robot<and>vertical force)<and> (gait<or>walking<or>running))<IN>metadata)
#2	(((mobile robot<and>vertical)<and> (gait<or>walking<or>running))<in>metadata)
#3	(((mobile robot<and>((restriction<or>limitation<or>range) vertical))<in>metadata)
#4	(((robot<and>((restriction<or>limitation<or>range) vertical)) <in>metadata)
#5	(((robot<and>((restriction<or>limitation<or>range) <near>vertical))<in>metadata)
#6	(((robot<and>((restriction<or>limitation<or>range) <with>vertical))<in>metadata)
#7	(((robot<and>((restriction<or>limitation<or>range) <and>vertical))<in>metadata)
#8	((robot<and>((restriction<or>limitation<or>range)<and>vertical)) <in>metadata)
#9	((robot<and>((restriction<or>limitation<or>range)<and>(gait stability)))<in>metadata)
#10	((robot<and>((angular momentum)<and>(maintain center of gravity)))<in>metadata)
#11	((robot<and>((angular momentum)<and>(center of gravity))) <in>metadata)
#12	((robot<and>((stability<or>balance)<and>(arm<or>upper body)) <and>(gait<or>walking<or>running))<in>metadata)
#13	((robot<and>((stability<or>balance)<and>(zmp<and> (vertical<or>z-axis))<and>(gait<or>walking<or>running)) <in>metadata)
#14	((robot<and>((stability<or>balance)<and>zmp<and> (vertical<or>z-axis)<and>(gait<or>walking<or>running)) <in>metadata)

#15   ((robot<and>((stability<or>balance)<and>(vertical<or>z-axis)
      <and>(gait<or>walking<or>running))<in>metadata)

#16   ((robot<and>(stability<or>balance)<and>(vertical<or>z-axis)
      <and>(gait<or>walking<or>running))<in>metadata)

#17   ((robot<and>((containment<or>restriction<or>restrict<or>limit)
      <and>(vertical<or>z-axis))<and>(gait<or>walking<or>running))
      <in>metadata)

#18   ((robot<and>((containment<or>restriction<or>restrict<or>limit)
      <and>(vertical<or>z-axis))<and>(gait<or>walking<or>running))
      <in>metadata)

#19   ((matsumoto)<in>au)

#20   ((takashi matsumoto)<in>au)

#21   ((matsumoto takashi)<in>au)

#22   ((yoshike)<in>au)

#23   ((takenaka)<in>au)

#24   (((takenaka)<in>au)<and>robot<in>metadata)